

UTILITY PATENT APPLICATION TRANSMITTAL

(Only for new nonprovisional applications under 37 CFR 1.53(b))

Attorney Docket No. 826.1553/JDH

First Named Inventor or Application Identifier:

Akira NAKAGAWA, et al.

Express Mail Label No.



APPLICATION ELEMENTS

See MPEP chapter 600 concerning utility patent application contents.

ADDRESS TO: Assistant Commissioner for Patents
Box Patent Application
Washington, DC 20231

1. ☒ Fee Transmittal Form
2. ☒ Specification, Claims & Abstract [Total Pages: 50]
3. ☒ Drawing(s) (35 USC 113) [Total Sheets: 16]
4. ☒ Oath or Declaration [Total Pages: 4]
 - a. ☒ Newly executed (original or copy)
 - b. ☐ Copy from a prior application (37 CFR 1.63(d)) (for continuation/divisional with Box 17 completed)
 - i. ☐ DELETION OF INVENTOR(S)
Signed statement attached deleting inventor(s) named in the prior application, see 37 CFR 1.63(d)(2) and 1.33(b).
5. ☐ Incorporation by Reference (usable if Box 4b is checked)
The entire disclosure of the prior application, from which a copy of the oath or declaration is supplied under Box 4b, is considered as being part of the disclosure of the accompanying application and is hereby incorporated by reference therein.
6. ☐ Microfiche Computer Program (Appendix)
7. ☐ Nucleotide and/or Amino Acid Sequence Submission (if applicable, all necessary)
 - a. ☐ Computer Readable Copy
 - b. ☐ Paper Copy (identical to computer copy)
 - c. ☐ Statement verifying identity of above copies

ACCOMPANYING APPLICATION PARTS

8. ☒ Assignment Papers (cover sheet & document(s))
9. ☐ 37 CFR 3.73(b) Statement (when there is an assignee) ☐ Power of Attorney
10. ☐ English Translation Document (if applicable)
11. ☒ Information Disclosure Statement (IDS)/PTO-1449 ☒ Copies of IDS Citations
12. ☐ Preliminary Amendment
13. ☒ Return Receipt Postcard (MPEP 503) (Should be specifically itemized)
14. ☐ Small Entity Statement(s) ☐ Statement filed in prior application, status still proper and desired.
15. ☒ Certified Copy of Priority Document(s) (if foreign priority is claimed)
16. ☐ Other:

17. If a CONTINUING APPLICATION, check appropriate box and supply the requisite information:

☐ Continuation ☐ Divisional ☐ Continuation-in-part (CIP) of prior application No:

18. CORRESPONDENCE ADDRESS

STAAS & HALSEY
Attn: James D. Halsey, Jr.
700 Eleventh Street, N.W., Suite 500
Washington, DC 20001Telephone: (202) 434-1500
Facsimile: (202) 434-1501

APPLICATION FOR
UNITED STATES LETTERS PATENT
SPECIFICATION

Inventor(s): Akira NAKAGAWA, Taizo ANAN, Eishi MORIMATSU,
and Takashi ITOH

Title of the Invention: MOTION VECTOR ENCODING DEVICE AND
DECODING DEVICE

MOTION VECTOR ENCODING DEVICE AND DECODING DEVICE**Background of the Invention****Field of the Invention**

5 The present invention relates to an encoding device and a decoding device for motion vector data of a moving image.

Description of the Related Art

10 Since an amount of data of a moving image is normally large, the data is encoded with a high efficiency coding when being transferred from a transmitting device to a receiving device or when being stored in a storage device. Here, the high
15 efficiency coding is an encoding process for converting a data sequence into a different data sequence, and for compressing its data amount.

 As a high efficiency coding method for moving image data, an interframe predictive coding is known.
20 This coding method takes advantage of the nature that the degree of correlation of moving image data is high in a time direction. Namely, the degree of similarity between frame data of moving image data at certain timing and that at the next timing is normally high
25 in many cases. Therefore, the interframe predictive

coding utilizes this nature. For example, in a data transmission system using the interframe predictive coding, a transmitting device generates motion vector data which represents a motion from an image in a preceding frame to an image in a target frame, and difference data (predictive error) between a predicted image in the target frame, which is generated from the image in the preceding frame by using the motion vector data, and an image in the target frame. The transmitting device then outputs the motion vector data and the difference data to a receiving device. The receiving device reproduces the image in the target frame from the received motion vector data and difference data.

If the degree of correlation between the target and preceding frames is high in the above described encoding process, the amounts of information of the motion vector data and the difference data become small.

The above described interframe predictive coding is employed by the standard methods such as the ITU-T H.261, ITU-T H.263, ISO/IEC MPEG-1, ISO/IEC MPEG-2, etc. Additionally, these standard methods utilize predictive coding as a method for encoding motion vector data. Hereinafter, a method for encoding motion

vector data will be explained by citing the ITU-T H.263 as an example.

With a predictive coding, an image in each frame is partitioned into a plurality of blocks (B11, B12, B13, B14, ...), and image data is encoded for each of the blocks. That is, an image similar to that in a target block is extracted from the image in the preceding frame, and the difference between the extracted image and the image in the target block is obtained for each of the blocks. In this way, differential image data from which redundancy is removed can be obtained. Also the motion vector data of the target block is obtained at this time. Then, data to be transmitted is compressed by encoding the differential image data and the motion vector data for each of the blocks.

When the motion vector data of a certain block (a target block to be encoded) is encoded, a predicted value of the motion vector (hereinafter referred to as a predictive vector) of the target block to be encoded is first obtained based on motion vectors of blocks adjacent to the target block. Here, blocks which have already been encoded are selected as the adjacent blocks used for this prediction. Normally, the encoding process is started from the block at the

upper left corner, and is performed for each block in each line as shown in Fig. 1. When a certain block is encoded in this case, the encoding process has already been performed for the blocks in the line above this
5 block and the block at the left thereof. Accordingly, for example, when the motion vector of a block B22 is encoded, the motion vectors of blocks B11 through B21 can be used.

When a motion vector of a target block to be
10 encoded is predicted with the ITU-T H.263, the block above the target block, the block at the upper right, and the block at the left are used. By way of example, when the motion vector of the block B22 shown in Fig. 1 is encoded, the motion vectors of the blocks B12,
15 B13, and B21 are used.

After the predictive vector of the target block to be encoded is obtained, the difference vector (or a prediction error vector) between a motion vector of the target block and its predictive vector is
20 obtained. Then, the X and Y components of the difference vector are respectively encoded by using variable-length codes. The variable-length codes are, for example, Huffman codes.

A specific example will be given by referring to
25 Fig. 2. This figure assumes that a motion vector of

a target block to be encoded is (MV_x, MV_y) , and respective motion vectors of adjacent blocks B1 through B3 used to obtain a predictive vector of the target block are respectively $(PMV1_x, PMV1_y)$, $(PMV2_x, PMV2_y)$, and $(PMV3_x, PMV3_y)$. Here, the X component of the predictive vector of the target block is obtained as a median value of $PMV1_x$, $PMV2_x$, and $PMV3_x$, while its Y component is obtained as a median value of $PMV1_y$, $PMV2_y$, and $PMV3_y$. Then, difference vector data (the X and the Y components of the difference vector) are obtained by the following equations.

difference vector data (x)

$$= MV_x - \text{Median}(PMV1_x, PMV2_x, PMV3_x)$$

difference vector data (y)

$$= MV_y - \text{Median}(PMV1_y, PMV2_y, PMV3_y)$$

Each of difference vector data is encoded by using the variable-length codes shown in Fig. 3. The codes shown in Fig. 3 are the ones used by the ITU-T H.263.

For these codes, a data sequence having a short data length is assigned to difference vector data whose occurrence frequency is high, while a data sequence having a long data length is assigned to difference vector data whose occurrence frequency is low. The occurrence frequencies of difference vector data are statistically obtained in advance. Since use

of such codes increases the probability that motion vector data having a short data length is transmitted, an average amount of information of motion vector data in each block decreases.

5 As described above, in a transmission system using an encoding method such as the ITU-T H.263, etc., data relating to a motion vector is compressed by using a predictive vector and the amount of information to be transmitted becomes small, which leads to an increase
10 of a transmission efficiency.

For the codes which are widely used by existing predictive coding, a data sequence having a short data length is assigned to small difference vector data as shown in Fig.3. In a scene where there is little or
15 no motion or in a scene where an image changes uniformly, the prediction accuracy of a predictive vector becomes high and the length of difference vector data becomes short. Accordingly, the amount of information of encoded motion vector data becomes
20 small on these scenes.

A specific example will be given by referring to Figs. 4A and 4B. Fig. 4A exemplifies motion vectors in a scene where there is little or no motion. This figure assumes that a motion vector of a target block
25 to be encoded is (1, 0), and motion vectors of blocks

B1 through B3, which are adjacent to the target block, are respectively (0, 0), (0, 0), and (1, 0). In this case, the X and the Y components of the predictive vector of the target block are respectively obtained
 5 by the following equations.

$$\text{predictive vector}(x) = \text{Median}(0, 0, 1) = 0$$

$$\text{predictive vector}(y) = \text{Median}(0, 0, 0) = 0$$

Accordingly, "predictive vector" = (0, 0) is obtained.

10 Furthermore, the difference vector of the target block to be encoded is obtained by the following equation.

$$\begin{aligned} \text{difference vector} &= \text{motion vector of the target} \\ &\text{block} - \text{predictive vector} \end{aligned}$$

$$\begin{aligned} 15 \quad &= (1, 0) - (0, 0) \\ &= (1, 0) \end{aligned}$$

For "difference vector data (difference vector component)=1", "0010" is obtained as encoded motion vector data if the codes shown in Fig. 3 are used. For
 20 "difference vector data=0", "1" is obtained as the encoded motion vector data. Accordingly, the encoded motion vector data to be transmitted for the target block is 5 bits.

As described above, in the scene where there is
 25 little or no motion, the difference vector data

becomes small, so that also the amount of information of encoded motion vector data to be transmitted becomes small.

Fig. 4B exemplifies motion vectors in a scene where an image changes almost uniformly across frames. This figure assumes that a motion vector of a target block to be encoded is $(10, -9)$, and motion vectors of blocks B1 through B3, which are adjacent to the target block, are respectively $(10, -10)$, $(9, -9)$, and $(9, -9)$. In this case, "difference vector= $(1, 0)$ " is obtained. Accordingly, even in the scene where an image changes uniformly, the difference vector data becomes small, so that also the amount of information of encoded motion vector data to be transmitted becomes small.

In a scene where an image does not change uniformly across frames, however, the prediction accuracy of a predictive vector becomes low and the difference vector data becomes large. Accordingly, the amount of information of encoded motion vector data to be transmitted becomes large on such a scene. Next, a specific example will be given by referring to Fig. 5.

Fig. 5 assumes that a motion vector of a target block to be encoded is $(4, 2)$, and motion vectors of

blocks B1 through B3, which are adjacent to the target block, are respectively $(-10, 4)$, $(-10, -10)$, and $(4, -10)$. In this case, a predictive vector of the target block is obtained by using the motion vectors of the adjacent blocks as follows.

predictive vector (x)

$$= \text{Median}(-10, -10, 4) = -10$$

predictive vector (y)

$$= \text{Median}(4, -10, -10) = -10$$

Consequently,

$$\text{predictive vector} = (-10, -10)$$

The difference vector of the target block is obtained by the following equation.

difference vector

$$\begin{aligned} &= \text{motion vector of target block} \\ &\quad - \text{predictive vector} \\ &= (4, 2) - (-10, -10) \\ &= (14, 12) \end{aligned}$$

For "difference vector data=12", "00000001000" is obtained as the motion vector data to be transmitted if the codes shown in Fig. 3 are used. Similarly, for "difference vector data=14", "000000001000" is obtained as the motion vector data to be transmitted. Accordingly, the encoded motion vector data to be transmitted for the target block is 23 bits. As

described above, in the scene where an image does not change uniformly, the difference vector data becomes large, so that also the amount of information of the encoded motion vector data to be transmitted becomes large.

As described above, moving image data is compressed with predictive coding in order to increase a transmission efficiency. However, its compression ratio is not sufficiently high depending on the nature of a moving image.

Summary of the Invention

An object of the present invention is to increase an encoding efficiency of a device which encodes moving image data by using predictive coding.

A motion vector encoding device according to the present invention has a configuration such that motion vectors of respective blocks obtained by partitioning each frame of moving image data are encoded. This device comprises: a predicting unit which predicts a motion vector of a target block based on motion vectors of a plurality of blocks which are adjacent to the target block; a determining unit which determines (or detects) the accuracy of a prediction made by the predicting unit based on the degrees of

non-uniformity of the plurality of motion vectors; and
an encoding unit which encodes the motion vector of
the target block by using the result of the prediction
made by the predicting unit with an encoding method
5 determined based on the result of the determination
made by the determining unit.

In the above described configuration, a predicted
value of a motion vector is used when the motion
vector is encoded. This predicted value is generated
10 based on the motion vectors of a plurality of blocks
which are adjacent to the target block. Here, if the
motion vectors of the blocks adjacent to the target
block are not uniform, that is, different one another,
the accuracy of the prediction made by the predicting
15 unit is expected to deteriorate. Accordingly, the
encoding unit selects a suitable encoding method
depending on prediction accuracy.

With the above described configuration, a motion
vector is encoded with an encoding method optimum for
20 the nature of moving image, thereby decreasing the
amount of information and increasing an encoding
efficiency.

A motion vector decoding device according to the
present invention decodes the motion vector data
25 encoded by the motion vector encoding device having

the above described configuration. The configuration and the operations of the motion vector decoding device according to the present invention are fundamentally the same as those of the above described motion vector encoding device.

Brief Description of the Drawings

Fig. 1 explains a process for partitioning a frame into blocks;

Fig. 2 exemplifies a prediction of a motion vector;

Fig. 3 exemplifies variable-length codes;

Figs. 4A and 4B explain the method for encoding motion vectors;

Fig. 5 explains the problems of a conventional coding;

Fig. 6 exemplifies a transmission system where a motion vector encoding device and a motion vector decoding device according to the present invention are used;

Fig. 7 is a block diagram showing the configuration of an interframe predictive coding device;

Fig. 8 shows the fundamental configuration of a motion vector encoding device according to a preferred

embodiment of the present invention;

Fig. 9 is a block diagram showing the configuration of the motion vector encoding device according to the preferred embodiment of the present invention;

Fig. 10 explains the operations of a prediction error generating unit;

Fig. 11 exemplifies variable-length codes;

Fig. 12 explains the operations of a first determining unit;

Fig. 13 explains the operations of a second determining unit;

Fig. 14 is a flowchart showing the process performed by the motion vector encoding device;

Fig. 15 is a block diagram exemplifying a motion vector decoding device according to a preferred embodiment of the present invention; and

Fig. 16 explains the operations of a vector regenerating unit.

Description of the Preferred Embodiments

A motion vector encoding device and a motion vector decoding device according to a preferred embodiment of the present invention are used, for example, in a system which transmits moving image data

and is shown in Fig. 6. In this transmission system, each frame of moving image data is partitioned into a plurality of blocks as shown in Fig. 1, and each of the plurality of blocks is encoded/decoded.

5 An interframe predictive coding device 10 comprises a coefficient encoding unit 11 and a motion vector encoding unit 12. This device encodes and outputs original image data. Note that the interframe predictive coding device 10 does not perform
10 interframe predictive coding for all of the frames, and, it has a capability for performing an intraframe coding depending on need.

 The coefficient encoding unit 11 generates encoded coefficient data obtained by encoding coefficient
15 information for each block. The motion vector encoding unit 12 generates encoded motion vector data obtained by encoding the information about a motion vector for each block.

 An interframe predictive decoding device 20
20 comprises a coefficient decoding unit 21 and a motion vector decoding unit 22. This device reproduces image data based on the encoded coefficient data and the encoded motion vector data, which are generated by the interframe predictive coding device 10.

25 The motion vector encoding device and the motion

vector decoding device according to this preferred embodiment respectively correspond to the motion vector encoding unit 12 and the motion vector decoding unit 22 in the system shown in Fig. 6.

5 Fig. 7 is a block diagram showing the configuration of an interframe predictive coding device. The configuration of this interframe predictive coding device is known, and is fundamentally the same as, for example, that used by
10 a coding method such as the ITU-T H.263, etc. The motion vector encoding device according to this preferred embodiment corresponds to a vector entropy encoding circuit 41 in Fig. 7, and the capability of this circuit is different from that of an existing
15 vector entropy encoding circuit. The configuration and the operations of the vector entropy encoding circuit 41 will be explained in detail later. Next, the operations of an existing circuit portion will be briefly explained.

20 When original image data is input for each frame, the interframe predictive coding device 10 performs an encoding process sequentially for a plurality of blocks obtained by partitioning each frame. An orthogonal transformation circuit 31 resolves the
25 image data into frequency components for each block.

A quantization circuit 32 quantizes the output of the orthogonal transformation circuit 31. The output of the quantization circuit 32 is sometimes referred to as "coefficient data".

5 An inverse quantization circuit 33, an inverse orthogonal transformation circuit 34, and a decoded image generating circuit 35 are arranged for generating the same image as that should be reproduced by the decoding device (the interframe predictive
10 decoding device 20 in Fig. 6). The image generated by these circuits is stored in a decoded image storing circuit 36.

 A motion vector calculation circuit 37 calculates a motion vector based on the image stored in the
15 decoded image storing circuit 36 and a newly input image. A method for obtaining a motion vector for each block is a known technique. A predicted image generating circuit 38 generates a predicted image based on the image stored in the decoded image storing
20 circuit 36 and the motion vector calculated by the motion vector calculation circuit 37. Namely, the predicted image generating circuit 38 predicts an image in a frame at the next timing from an image in a frame at certain timing, and outputs the image. This
25 predicted image is an image generated also in the

decoding device.

A prediction error signal generating circuit 39 generates a signal representing an error between an input image and a predicted image generated by the predicted image generating circuit 38. This prediction error signal is a signal to be transmitted to the decoding device. The prediction error signal is encoded and transmitted. First of all, coefficient data of the prediction error signal is obtained by the orthogonal transformation circuit 31 and the quantization circuit 32. A coefficient entropy encoding circuit 40 then encodes and outputs the coefficient data.

Note that the interframe predictive coding device 10 may sometimes perform interframe coding depending on need. In this case, not the predicted image generated by the predicted image generating circuit 38, but "0" is provided to the prediction error signal generating circuit 39.

The vector entropy encoding circuit 41 encodes motion vector data for each block. A multiplexing circuit 42 multiplexes the encoded coefficient data encoded by the coefficient entropy encoding circuit 40 and the encoded motion vector data encoded generated by the vector entropy encoding circuit 41,

and outputs the multiplexed data.

As described above, the decoding device generates the same predicted image as that generated by the interframe predictive coding device 10. The decoding device then reproduces the original image by using the predicted image, the received prediction error signal, and the motion vector.

Fig. 8 shows the fundamental configuration of the motion vector encoding device according to this preferred embodiment. This encoding device corresponds to the vector entropy encoding circuit 41 in Fig. 7.

Likewise an existing encoding device, when encoding a motion vector of a target block to be encoded, the motion vector encoding device 50 according to this preferred embodiment performs: (1) the operation for generating a predictive vector of the target block from the motion vectors of blocks adjacent to the target block; (2) the operation for obtaining a difference vector between an actual motion vector of the target block and its predictive vector; and (3) the operation for generating encoded motion vector data by encoding each component of the difference vector.

The motion vector encoding device 50 comprises a determining unit 51, encoding units 52a through 52n,

and a selecting unit 53. Motion vectors of some or all of the blocks within the frame to which the target block to be encoded belongs (motion vectors for determination) are provided to the determining unit

5 51. The determining unit 51 selects from among the provided motion vectors a plurality of motion vectors of the blocks which have been encoded and are adjacent to the target block. The determining unit 51 then estimates the prediction accuracy of a predictive

10 vector based on the selected motion vectors. To be more specific, the determining unit 51 estimates the prediction accuracy of the predictive vector based on the degrees of "non-uniformity" or "uniformity" of the selected motion vectors.

15 "Uniformity of a plurality of motion vectors" means that the plurality of motion vectors in a frame are the same each other. For example, on a scene where there is no motion across frames, motion vectors of all of blocks are "0 vectors" or a vector having a

20 short length as shown in Fig. 4A. That is, the plurality of motion vectors are uniform or almost uniform. Furthermore, on a scene where an image changes almost uniformly across frames, motion vectors of respective blocks have a certain length, and their

25 lengths and directions are almost equal each other.

Namely, the plurality of motion vectors are almost uniform also in this case.

"Non-uniformity of a plurality of motion vectors" means that the motion vectors of a plurality of adjacent blocks are different one another (not uniform). By way of example, on a scene where an image does not change uniformly across frames, the motion vectors of respective blocks are not uniform as shown in Fig. 5.

The motion vectors of the target block to be encoded and the blocks adjacent to the target block are provided to each of the encoding units 52a through 52n. At this time, the encoding units 52a through 52n may use the motion vectors of the adjacent blocks which are the same motion vectors used by the determining unit 51 when the prediction accuracy of the predictive vector is estimated, or different motion vectors.

The encoding units 52a through 52n generate a predictive vector from the plurality of motion vectors for prediction, and obtain a difference vector between the motion vector of the target block to be encoded and its predictive vector. The difference vector is a vector representing a prediction error. The respective encoding units 52a through 52n encode the

respective components of the difference vector by using different codes.

The selecting unit 53 selects one of the encoding units 52a through 52n based on the prediction accuracy
5 estimated by the determining unit 51. Specifically, the selecting unit 53 selects an encoding unit so that the amount of information of the result of encoding performed by the motion vector encoding device 50 becomes a minimum. The selecting unit 53 then outputs
10 the result of the encoding performed by the selected encoding unit as the encoded motion vector data.

In the above described configuration, when encoding the motion vector of the target block to be encoded, the determining unit 51 estimates the
15 prediction accuracy of the predictive vector by using the motion vectors of the blocks which have been encoded in the frame. The selecting unit 53 selects an encoding unit according to the prediction accuracy thus estimated. Namely, with this encoding device, an
20 encoding method is determined based on the motion vectors which have been encoded in the frame, when the motion vector data of the target block to be encoded is encoded.

With such a configuration, a decoding device can
25 recognize the encoding method selected by the encoding

device without receiving the information about the encoding method. That is, if the configuration of the decoding device is made equivalent to that of the encoding device, the motion vectors used to determine the encoding method with which the target motion vector has been encoded, have already been decoded within the decoding device when the target motion vector is decoded. Accordingly, the decoding device can recognize the encoding method selected by the encoding device with the motion vectors which have already been decoded. The decoding device then decodes the received data with the decoding method corresponding to the encoding method that the decoding device itself recognizes.

If there is little or no motion, or if an image changes uniformly across frames in the above described configuration, the prediction accuracy of the predictive vector of the target block to be encoded is normally high. If the prediction accuracy is high, the possibility that the difference vector becomes small increases. If an image does not change uniformly across frames, normally, the prediction accuracy of the predictive vector becomes low, which leads to an increase in the possibility that the difference vector becomes large. This nature has been statistically

analyzed. Therefore, the probability distribution of the occurrence frequency of the size of the difference vector can be estimated according to the nature of an image.

5 In this preferred embodiment, an encoding method is determined for each block in consideration of this nature. That is, when encoding the motion vector of the target block to be encoded, the motion vector encoding device 50 recognizes the nature of an image
10 in an adjacent area by using the motion vectors of adjacent blocks, and selects an encoding method based on the recognition result. Accordingly, an encoding method which is optimum or suitable for the nature of the image can be selected. Here, "optimum" means that
15 the amount of information of the encoded motion vector data obtained as an encoding result becomes a minimum.

Fig. 9 is a block diagram showing the configuration of the motion vector encoding device according to this preferred embodiment. A motion
20 vector encoding device 60 respectively encodes the X and the Y components of a motion vector. A first determining unit 61, a prediction error generating unit 62, variable-length coding units 63a and 63b, and a first selecting unit 64 operate in order to encode
25 the X component of the motion vector, while a second

determining unit 65, a prediction error generating unit 66, variable-length coding units 67a and 67b, and a second selecting unit 68 operate in order to encode the Y component.

5 The configuration for encoding the X component and that for encoding the Y component may be the same. However, these configurations are different in the encoding device according to this preferred embodiment. Specifically, the capabilities of the
10 first and the second determining units 61 and 65 are different each other.

 The prediction error generating unit 62 generates the X component of the difference vector as prediction error data. The method for generating a difference
15 vector is fundamentally the same as that used by an encoding method such as the ITU-T H.263, etc. Next, the operations of the prediction error generating unit 62 will be explained by referring to Fig. 10.

 The X components of the motion vectors of a target
20 block to be encoded and a plurality of adjacent blocks are provided to the prediction error generating unit 62. The adjacent blocks used at this time are the block above the target block, the block at the upper right, and the block at the left thereof. The motion
25 vectors of these 3 blocks have been encoded when the

motion vector of the target block is encoded.

The prediction error generating unit 62 obtains a median value (that is, an intermediate value) among the provided X components of the 3 motion vectors.

5 This median value corresponds to the X component of a predictive vector. The prediction error generating unit 62 then outputs the difference between the X component of the motion vector of the target block and its median value (the X component of the predictive

10 vector). This difference data is a prediction error value of the X component, and corresponds to the X component of the difference vector.

In this preferred embodiment, a prediction error is generated with the same algorithm for the

15 respective encoding methods provided by the variable-length coding units 63a and 63b. That is to say, the prediction error generating unit 62 is shared by the variable-length coding units 63a and 63b. In other words, the prediction error data generated by the

20 prediction error generating unit 62 is provided to the variable-length coding units 63a and 63b in parallel.

The configuration of the prediction error generating unit 66 is fundamentally the same as that of the prediction error generating unit 62, and is

25 intended to generate the prediction error data of the

Y component.

The variable-length encoding units 63a and 63b encode the prediction error data that the prediction error generating unit 62 generates by using different variable-length codes. The variable-length coding unit 63a utilizes variable-length codes 1 shown in Fig. 11. The variable-length codes 1 are codes used by the ITU-T H.263, etc. A data sequence having a short data length is assigned to a small prediction error (difference value), while a data sequence having a long data length is assigned to a large prediction error. Accordingly, if the motion vectors of a plurality of adjacent blocks are uniform, the possibility that a prediction error becomes small is strong. Therefore, the data length of an encoding result becomes short if the variable-length codes 1 are used for this kind of moving image. That is, if there is little or no motion, or an image changes uniformly across frames, an average data length of an encoding result becomes short by using the variable-length codes 1, which leads to an improvement in an encoding efficiency.

The variable-length coding unit 63b utilizes the variable-length codes 2 shown in Fig. 11. Compared with the variable-length codes 1, the data length of

an encoding result obtained with the variable-length codes 2 becomes longer if a prediction error is small, while the data length of an encoding result becomes short if the prediction error is large. Assuming that
5 the prediction error is 15.5, the data length of the encoding result obtained with the variable-length codes 1 is 13 bits, while the data length of the encoding result obtained with the variable-length codes 2 is 8 bits.

10 Accordingly, if the motion vectors of a plurality of adjacent blocks are not uniform, the possibility that the accuracy of a predictive vector becomes low and a prediction error becomes large, is stronger. Therefore, with the variable-length codes 2, the data
15 length of an encoding result is expected to become short for this kind of moving image. That is, if an image does not change uniformly across frames, etc., use of the variable-length codes 2 allow an average data length of an encoding result to become shorter.
20 As a result, an encoding efficiency increases.

The variable-length coding units 63a and 63b comprise the tables which are shown in Fig. 11 and encoding patterns are registered to. These tables are generated in memory. The variable-length coding units
25 63a and 63b obtain a corresponding data sequence from

the tables by using provided prediction error data as a key, and outputs the obtained data sequence as an encoding result.

5 The variable-length coding units 67a and 67b are fundamentally the same as the variable-length coding units 63a and 63b. The variable-length coding units 67a and 67b encode the prediction error data that the prediction error generating unit 66 generates by using the variable-length codes 1 and 2.

10 The first determining unit 61 estimates the accuracy of the predictive vector of the target block to be encoded, and generates a selection instruction to be given to the first selecting unit 64 based on the result of the estimation. Since the accuracy of
15 the predictive vector is estimated based on the motion vectors of blocks adjacent to the target block, the accuracy depends on the nature of an image in an adjacent area.

20 The selection instruction generated by the first determining unit 61 is a signal for specifying either the variable-length coding unit 63a or 63b, which is expected to minimize the amount of information of an encoding result. Next, the operations of the first determining unit 61 will be explained by referring to
25 Fig. 12.

The first determining unit 61 determines the degrees of "uniformity" or "non-uniformity" of the motion vectors of the adjacent blocks based on the motion vectors of the above described 3 adjacent blocks. Specifically, if at least one of the following conditions 1 and 2 is satisfied, the first determining unit 61 determines that the motion vectors are "not uniform". If neither of the conditions 1 and 2 is satisfied, the first determining unit 61 determines that the motion vectors are "uniform".

condition 1 : $|PMV1_x - PMV2_x| > \text{threshold value 1}$ and
 $|PMV1_x - PMV3_x| > \text{threshold value 1}$ and
 $|PMV2_x - PMV3_x| > \text{threshold value 1}$
 condition 2 : $|PMV1_y - PMV2_y| > \text{threshold value 1}$ and
 $|PMV1_y - PMV3_y| > \text{threshold value 1}$ and
 $|PMV2_y - PMV3_y| > \text{threshold value 1}$

In the above described algorithm, the motion vectors are determined to be "not-uniform" if at least one of the X and the Y components of the motion vectors of the adjacent blocks are not uniform. Notice that the threshold value 1 is determined by conducting a simulation or an experiment.

If the first determining unit 61 determines that the motion vectors of the adjacent blocks are uniform, it recognizes that there is little or no motion or an

image changes uniformly across frames in the area adjacent to the target block to be encoded, and the prediction accuracy of the predictive vector is high. The first determining unit 61 therefore instructs the first selecting unit 64 to select the result of the encoding performed by the variable-length coding unit 63a. If the first determining unit 61 determines that the motion vectors of the adjacent blocks are not uniform, it recognizes that the image does not change uniformly across frames in the area adjacent to the target block, and the prediction accuracy of the predictive vector is low. The first determining unit 61 therefore instructs the first selecting unit 64 to select the result of the encoding performed by the variable-length coding unit 63b.

Upon receipt of the instruction from the first determining unit 61, the first selecting unit 64 selects and outputs the result of the encoding performed by the variable-length coding unit 63a or 63b according to this instruction. The output of the first selecting unit 64 is the X component of encoded motion vector data.

The second determining unit 65 estimates the accuracy of the predictive vector of the target block to be encoded in a similar manner as in the first

determining unit 61, and generates a selection instruction to be given to the second selecting unit 68 based on the result of the estimation. This instruction is a signal for specifying the variable-length coding unit which is expected to minimize the amount of information of the result of the encoding performed by the variable-length coding unit 67a or 67b. Note that the second determining unit 65 estimates the accuracy of the predictive vector based on criteria different from those of the first determining unit 61. Next, the operations of the second determining unit 65 will be explained by referring to Fig. 13.

To the second determining unit 65, not only the motion vectors of the above described 3 adjacent blocks but also the X component of the target motion vector to be encoded is provided. Here, the motion vector encoding device 60 is assumed to encode the Y component of the target motion vector after encoding its X component (MV_x).

If at least one of the following conditions 1 through 3 is satisfied, the second determining unit 65 determines that the motion vectors are "not uniform". If none of the conditions 1 through 3 are satisfied, the second determining unit 65 determines

that the motion vectors are "uniform".

condition 1 : $|PMV1_x - PMV2_x| > \text{threshold value 1}$ and
 $|PMV1_x - PMV3_x| > \text{threshold value 1}$ and
 $|PMV2_x - PMV3_x| > \text{threshold value 1}$

5 condition 2 : $|PMV1_y - PMV2_y| > \text{threshold value 1}$ and
 $|PMV1_y - PMV3_y| > \text{threshold value 1}$ and
 $|PMV2_y - PMV3_y| > \text{threshold value 1}$

condition 3 : $|MV_x - \text{Median}(PMV1_x, PMV2_x, PMV3_x)|$
 $> \text{threshold value 2}$

10 In condition 3, $\text{Median}(PMV1_x, PMV2_x, PMV3_x)$ is an arithmetic operation for obtaining the X component of a predictive vector. That is, condition 3 is intended to determine whether or not the X component of the target motion vector to be encoded is far from a
15 predicted value. The predicted value is calculated from the motion vectors of adjacent blocks. Therefore, condition 3 is used to detect that "only the target motion vector is much different from the motion vectors of the adjacent blocks in a state where the
20 motion vectors of the adjacent blocks are uniform".

If none of the above described 3 conditions are satisfied, the second determining unit 65 instructs the second selecting unit 68 to select the result of the encoding performed by the variable-length coding
25 unit 67a. If at least one of the conditions 1 through

3 is satisfied, the second determining unit 65 instructs the second selecting unit 68 to select the result of the encoding performed by the variable-length coding unit 67b.

5 Upon receipt of the instruction from the second determining unit 65, the second selecting unit 68 selects the result of the encoding performed by the variable-length coding unit 67a or 67b according to the instruction, and outputs the selected result in
10 a similar manner as in the first selecting unit 64. The output of the second selecting unit 68 is the Y component of encoded motion vector data.

 As described above, the adoption of the third condition enables the second determining unit 65 to
15 estimate the possibility that a prediction error becomes large, with higher accuracy than that of the first determining unit 61. Consequently, the possibility that an optimum encoding method can be selected becomes strong in the second determining unit
20 65, so that an encoding efficiency further increases.

 Fig. 14 is a flowchart showing the operations performed by the motion vector encoding device 60. The process of this flowchart is performed each time one motion vector is encoded.

25 Steps S1 through S5 are the operations for

encoding the X component. In step S1, a method for encoding the X component of a target vector is determined based on the vectors which have already been encoded. This operation is performed by the first
5 determining unit 61.

Steps S2 through S4 are the operations for encoding the X component of the target vector with encoding methods 1 through N. To be specific, a prediction error is calculated, and it is encoded with
10 the encoding methods 1 through N, respectively. These operations are performed by the prediction error generating unit 62 and the variable-length coding units 63a and 63b.

In step S5, the encoding result obtained with the
15 encoding method which is determined in step S1 is selected from among the encoding results generated in steps S2 through S4, and the selected result is output. This operation is performed by the first selecting unit 64.

20 Steps S6 through S10 are the operations for encoding the Y component. In step S6, a method for encoding the Y component of the target vector is determined based on the vectors which have already been encoded and the X component of the target vector.
25 This operation is performed by the second determining

unit 65.

Steps S7 through S9 are fundamentally the same as steps S2 through S4. The Y component of the target vector is encoded with the respective encoding methods 1 through N. Specifically, a prediction error is calculated, and it is encoded with the encoding methods 1 through N, respectively. These operations are performed by the prediction error generating unit 66 and the variable-length coding units 67a and 67b.

10

Step S10 is fundamentally the same as step S5. In this step, the encoding result obtained with the encoding method which is determined in step S6 is selected from among the encoding results generated in steps S7 through S9, and the selected result is output. This operation is performed by the second selecting unit 68.

15

The respective units 61 through 68 within the motion vector encoding device 60, which are shown in Fig. 9, may be implemented by software or hardware. If they are implemented by software, the motion vector encoding device 60 comprises at least a CPU and a memory, and offers the capabilities explained by referring to Figs. 9 through 13 by making the CPU execute the program describing the process of the

20

25

flowchart shown in Fig. 14.

Described next is a device for decoding the motion vector which is encoded by the motion vector encoding device having the above described configuration.

5 Fig. 15 is a block diagram showing the configuration of a motion vector decoding device according to a preferred embodiment. A motion vector decoding device 70 comprises a first determining unit 61, a first selecting unit 64, a second determining unit 65, and a second selecting unit 68. These units
10 61, 64, 65, and 68 are the same as those arranged within the motion vector encoding device 60. Variable-length decoding units 71a, 71b, 73a, and 73b perform decoding processes corresponding to the variable-length coding units 63a, 63b, 67a, and 67b. That is,
15 the variable-length decoding units 71a and 73a decode encoded motion vector data by using the variable-length codes 1, while the variable-length decoding units 71b and 73b decode encoded motion vector data
20 by using the variable-length codes 2.

The motion vector decoding device 70 decodes encoded motion vector data for each block in the same order as the encoding order of the motion vector encoding device 60. In other words, the motion vector
25 decoding device 70 regenerates the motion vectors from

the encoded motion vector data for the respective blocks in the order shown in Fig. 1. Since the motion vector encoding device 60 encodes a target vector by using the vectors which have been encoded prior to the target vector, the vectors used for encoding the target vector have already been decoded when the motion vector decoding device 70 decodes the target vector. For example, when the motion vector of the target block shown in Fig. 2 is decoded, all of the motion vectors of the adjacent blocks B1 through B3 have been decoded by the motion vector decoding device 70. Accordingly, in this case, the motion vector decoding device 70 can use the motion vectors of the adjacent blocks B1 through B3 when decoding the target motion vector.

In the above described configuration, the first determining unit 61 determines the decoding method based on the motion vectors of the 3 adjacent blocks. The 3 motion vectors used at this time are regenerated from the encoded motion vector data that the motion vector decoding device 70 receives. Namely, the first determining unit 61 can recognize the encoding method without receiving additional information indicating the encoding method from the motion vector encoding device 60.

The variable-length decoding units 71 and 71b respectively regenerate prediction errors from the encoded motion vector data received from the motion vector encoding device 60. The first selecting unit
5 64 selects the result of the decoding performed by the variable-length decoding unit 71a or 71b according to the instruction from the first determining unit 61, and outputs the selected result. The output of the first selecting unit 64 is a prediction error of the
10 X component.

As shown in Fig. 16, the vector regenerating unit 72 is provided the respective X components of the motion vectors of the adjacent blocks, and outputs their median value. The median value is the X
15 component of a predictive vector. The vector regenerating unit 72 then regenerates the X component of the motion vector of the target block by adding a prediction error, which is the output of the first selecting unit 64, to the X component of the
20 predictive vector.

The operations for regenerating the Y component of the motion vector of the target block are fundamentally the same as those for regenerating the X component. Remember that, however, the second
25 determining unit 65 utilizes not only the motion

vectors of adjacent blocks but also the X component of the motion vector of the target block, which is regenerated by the vector regenerating unit 72, in order to determine the decoding method. This utilization is the same as that explained by referring to Fig. 13.

As described above, a motion vector of a target block is encoded with an encoding method determined based on the motion vectors of blocks adjacent to the target block, according to this preferred embodiment. Furthermore, the encoded motion vector data of the target block is decoded with the decoding method determined based on the motion vectors of the blocks adjacent to the target block. Accordingly, an optimum code can be used in correspondence with a local nature of moving image, so that an encoding efficiency increases.

In the above described preferred embodiment, an encoding method is determined by using the motion vectors of the 3 adjacent blocks. The present invention, however, is not limited to this configuration. The present invention is also applicable to the configuration where motion vectors of a plurality of adjacent blocks are used.

Furthermore, the above described preferred

embodiment assumes a system which transmits image data. The present invention, however, is not limited to this configuration. For example, the present invention is also applicable to a device which stores
5 image data.

According to the present invention, a target vector is encoded with an optimum encoding method which is determined based on a plurality of motion vectors which have already been encoded in an area
10 adjacent to the target motion vector, thereby reducing the amount of information of an encoding result. Furthermore, when the data thus encoded is decoded, the decoding method corresponding to the encoding method can be recognized without requiring the
15 additional information indicating the encoding method.

What is claimed is:

1. A motion vector encoding device for encoding motion vectors of respective blocks obtained by partitioning each frame of moving image data, comprising:

predicting means for predicting a motion vector of a target block based on motion vectors of a plurality of blocks adjacent to the target block;

determining means for determining accuracy of a prediction made by said predicting means based on degrees of non-uniformity of the plurality of motion vectors; and

encoding means for encoding the motion vector of the target block using a result of the prediction made by said predicting means with an encoding method determined based on a result of a determination made by said determining means.

2. The motion vector encoding device according to claim 1, wherein said determining means determines the accuracy of the prediction made by said predicting means based on the degrees of non-uniformity of the plurality of motion vectors which have already been encoded in an area adjacent to the target block.

3. The motion vector encoding device according to claim 1, wherein said encoding means comprises:

a plurality of individual encoding means for encoding the motion vector of the target block with
5 unique encoding methods; and

selecting means for selecting one of said plurality of individual encoding means based on the result of the determination made by said determining means, and for outputting a result of encoding
10 performed by the selected individual encoding means;

4. The motion vector encoding device according to claim 3, wherein said plurality of individual encoding means respectively encode the motion vector
15 of the target block by using different variable-length codes.

5. The motion vector encoding device according to claim 1, wherein:

20 said predicting means comprises first and second predicting means for respectively predicting first and second components of the motion vector of the target block;

said determining means comprises
25 first determining means for determining

the accuracy of the prediction made by said first predicting means based on degrees of non-uniformity of respective first components of the plurality of motion vectors, and

5 second determining means for determining the accuracy of the prediction made by said second predicting means based on degrees of non-uniformity of respective second components of the plurality of motion vectors, a first component of the motion vector
10 of the target block, and the respective first components of the plurality of motion vectors; and

 said encoding means comprises

 first encoding means for encoding the first component of the motion vector of the target
15 block by using a result of a prediction made by said first predicting means with an encoding method determined based on a result of a determination made by said first determining means, and

 second encoding means for encoding the
20 second component of the motion vector of the target block by using a result of a prediction made by said second predicting means with an encoding method determined based on a result of a determination made by said second determining means.

25

6. A motion vector encoding device for encoding motion vectors of respective blocks obtained by partitioning each frame of moving image data, comprising:

5 predicting means for predicting a motion vector of a target block based on motion vectors of a plurality of other blocks within a frame to which the target block belongs;

10 determining means for determining accuracy of a prediction made by said predicting means based on degrees of non-uniformity of the plurality of motion vectors which have already been encoded within the frame to which the target block belongs; and

15 encoding means for encoding the motion vector of the target block by using a result of the prediction made by said predicting means with an encoding method determined based on a result of a determination made by said determining means.

20 7. A motion vector encoding device, which is arranged within an interframe predictive coding device for encoding moving image data by using a plurality of motion vectors, for encoding a motion vector, comprising:

25 predicting means for predicting a target motion

vector based on a plurality of motion vectors adjacent to the target motion vector;

determining means for determining accuracy of a prediction made by said predicting means based on
5 degrees of non-uniformity of the plurality of motion vectors; and

encoding means for encoding the target motion vector by using a result of a prediction made by said predicting means with an encoding method determined
10 based on a result of a determination made by said determining means.

8. A motion vector encoding device for encoding motion vectors of respective blocks obtained
15 by partitioning each frame of moving image data, comprising:

recognizing means for recognizing a nature of an image in an area adjacent to a target block; and

encoding means for encoding a motion vector of the
20 target block with an encoding method determined based on a result of recognition made by said recognizing means.

9. A motion vector encoding device for encoding
25 motion vectors of respective blocks obtained by

partitioning each frame of moving image data,
comprising:

a predictor which predicts a motion vector of a
target block based on motion vectors of a plurality
5 of blocks adjacent to the target block;

a detector which detects accuracy of a prediction
made by said predictor based on degrees of non-
uniformity of the plurality of motion vectors; and

an encoder which encodes the motion vector of the
10 target block using a result of the prediction made by
said predictor with an encoding method determined
based on a detected result by said detector.

10. A motion vector encoding method for
15 encoding motion vectors of respective blocks obtained
by partitioning each frame of moving image data,
comprising the steps of:

predicting a motion vector of a target block based
on motion vectors of a plurality of blocks adjacent
20 to the target block;

determining accuracy of the prediction based on
degrees of non-uniformity of the plurality of motion
vectors; and

encoding the motion vector of the target block by
25 using a result of the prediction with an encoding

method determined based on a result of a determination of the accuracy of the prediction.

11. A motion vector decoding device for
5 decoding an encoding result which is obtained by encoding motion vectors of respective blocks obtained by partitioning each frame of moving image data, comprising:

predicting means for predicting a motion vector of
10 a target block based on motion vectors of a plurality of blocks adjacent to the target block;

determining means for determining accuracy of a prediction made by said predicting means based on degrees of non-uniformity of the plurality of motion
15 vectors; and

decoding means for decoding the motion vector of the target block by using a result of the prediction made by said predicting means with a decoding method determined based on a result of a determination made
20 by said determining means.

12. A motion vector decoding device for
decoding an output of a motion vector encoding device which predicts a motion vector of a target block based
25 on motion vectors of a plurality of blocks adjacent

to the target block, determines accuracy of a prediction based on degrees of non-uniformity of a plurality of motion vectors which have already been encoded in an area adjacent to the target block, and
5 encodes the motion vector of the target block by using a result of the prediction with an encoding method determined based on a result of a determination of the accuracy of the prediction, in order to encode motion vectors of respective blocks obtained by partitioning
10 each frame of moving image data, comprising:

predicting means for predicting the motion vector of the target block based on the plurality of motion vectors used to make the determination within the motion vector encoding device;

15 determining means for determining accuracy of a prediction made by said predicting means based on the degrees of non-uniformity of the plurality of motion vectors; and

20 decoding means for decoding the motion vector of the target block by using a result of the prediction made by said predicting means with a decoding method determined based on a result of a determination made by said determining means.

25 13. A motion vector decoding method for

decoding a result of encoding obtained by encoding motion vectors of respective blocks obtained by partitioning each frame of moving image data, comprising the steps of:

5 predicting a motion vector of a target block based on motion vectors of a plurality of blocks adjacent to the target block;

 determining accuracy of a prediction based on degrees of non-uniformity of the plurality of motion
10 vectors; and

 decoding the motion vector of the target block by using a result of the prediction with a decoding method determined based on a result of a determination of the accuracy of the prediction.
15

Abstract of the Disclosure

A prediction error generating unit generates a predictive vector from the motion vectors of a plurality of adjacent blocks, and obtains a difference from a target vector. A plurality of variable-length coding units respectively encode the output of the prediction error generating unit with different encoding methods. A determining unit estimates the accuracy of the predictive vector generated by the prediction error generating unit based on the degrees of non-uniformity of the motion vectors of the plurality of adjacent blocks. A selecting unit selects one of the encoding results obtained by the plurality of variable-length coding units.

B_{11}	B_{12}	B_{13}	B_{14}	
B_{21}	B_{22}	B_{23}	B_{24}	
B_{31}	B_{32}	B_{33}	B_{34}	
B_{41}	B_{42}	B_{43}	B_{44}	
⋮				

FIG. 1

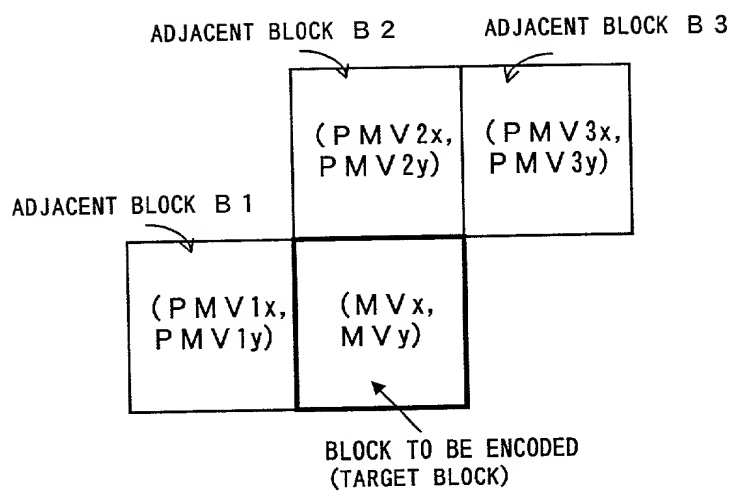


FIG. 2

DIFFERENCE	H.263 MVD
-16.0	0000000000101
-15.5	0000000000111
-15.0	000000000101
-14.5	000000000111
-14.0	000000001001
-13.5	000000001011
-13.0	000000001101
-12.5	000000001111
-12.0	00000001001
-11.5	00000001011
-11.0	00000001101
-10.5	00000001111
-10.0	00000010001
-9.5	00000010011
-9.0	00000010101
-8.5	00000010111
-8.0	00000011001
-7.5	00000011011
-7.0	00000011101
-6.5	00000011111
-6.0	00000100001
-5.5	00000100011
-5.0	0000010011
-4.5	0000010101
-4.0	0000010111
-3.5	00000111
-3.0	00001001
-2.5	00001011
-2.0	0000111
-1.5	00011
-1.0	0011
-0.5	011
-0.0	1

0.5	010
1.0	0010
1.5	00010
2.0	0000110
2.5	00001010
3.0	00001000
3.5	00000110
4.0	0000010110
4.5	0000010100
5.0	0000010010
5.5	00000100010
6.0	00000100000
6.5	00000011110
7.0	00000011100
7.5	00000011010
8.0	00000011000
8.5	00000010110
9.0	00000010100
9.5	00000010010
10.0	00000010000
10.5	00000001110
11.0	00000001100
11.5	00000001010
12.0	000000001000
12.5	000000001110
13.0	000000001100
13.5	000000001010
14.0	000000001000
14.5	000000000110
15.0	000000000100
15.5	0000000000110

F I G. 3

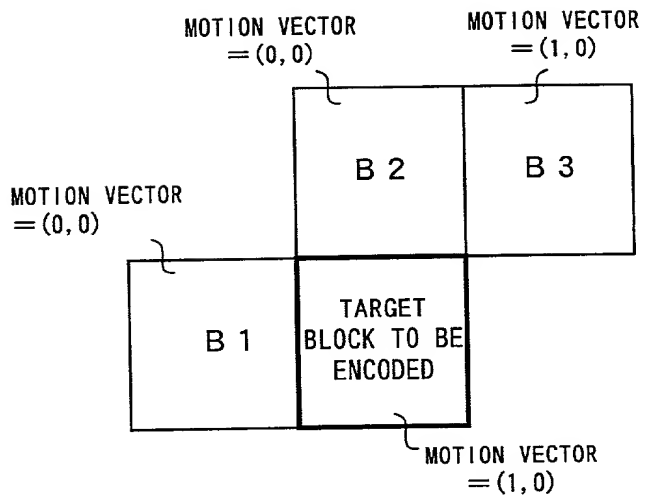


FIG. 4A

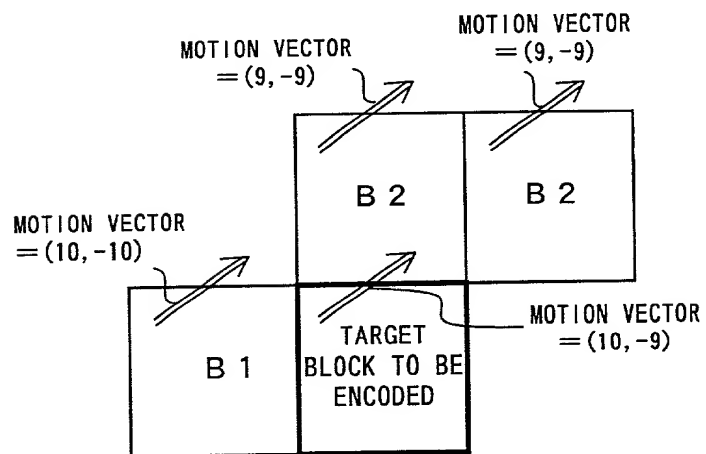


FIG. 4B

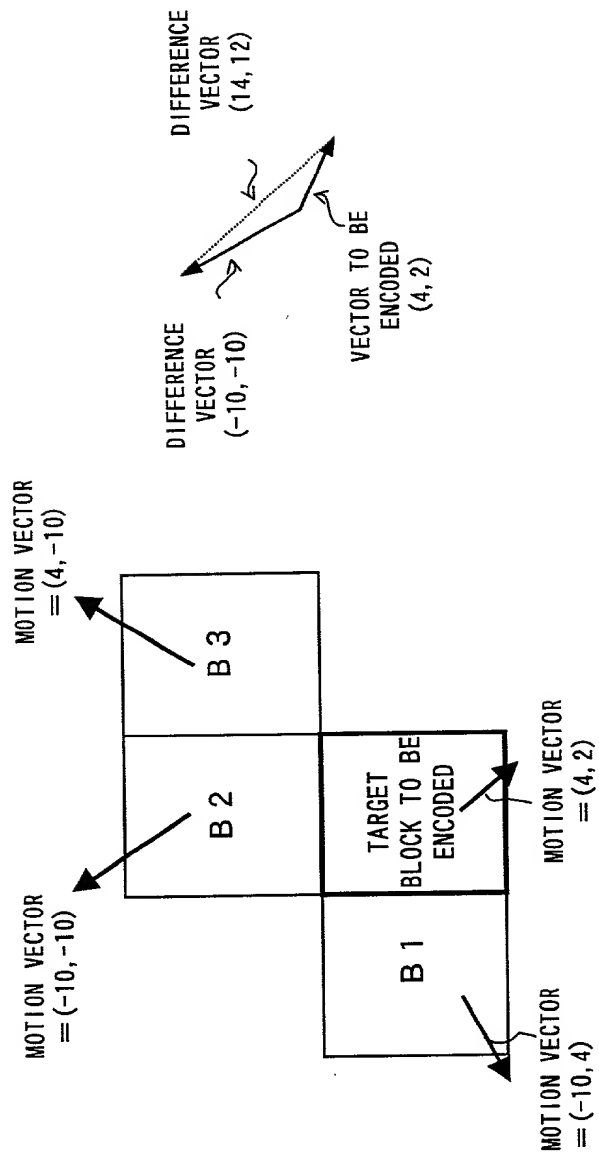


FIG. 5

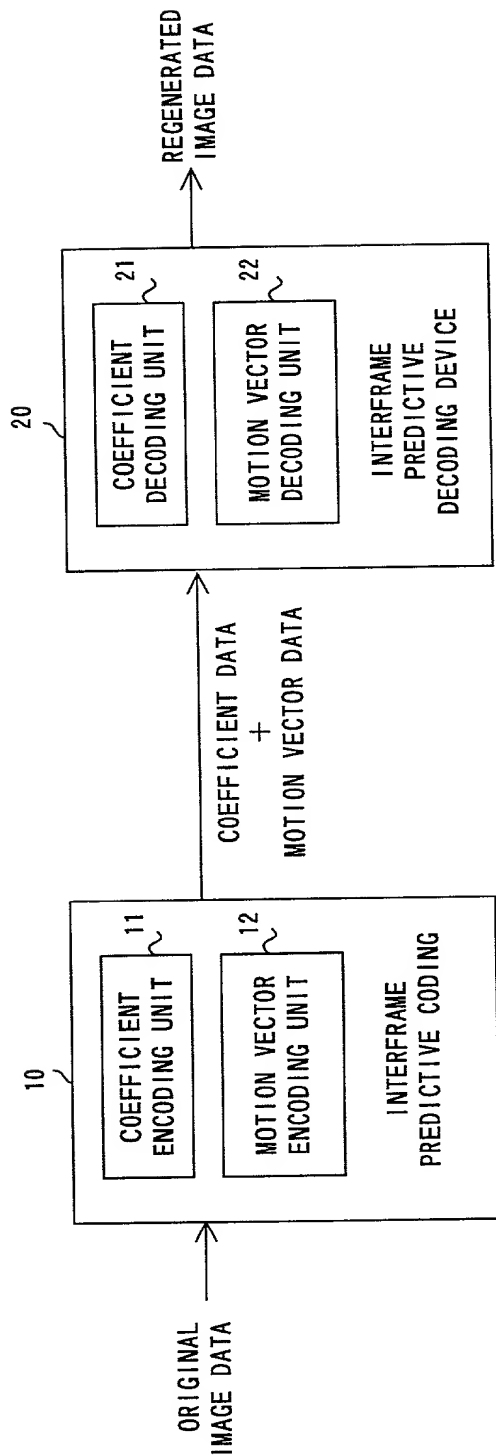


FIG. 6

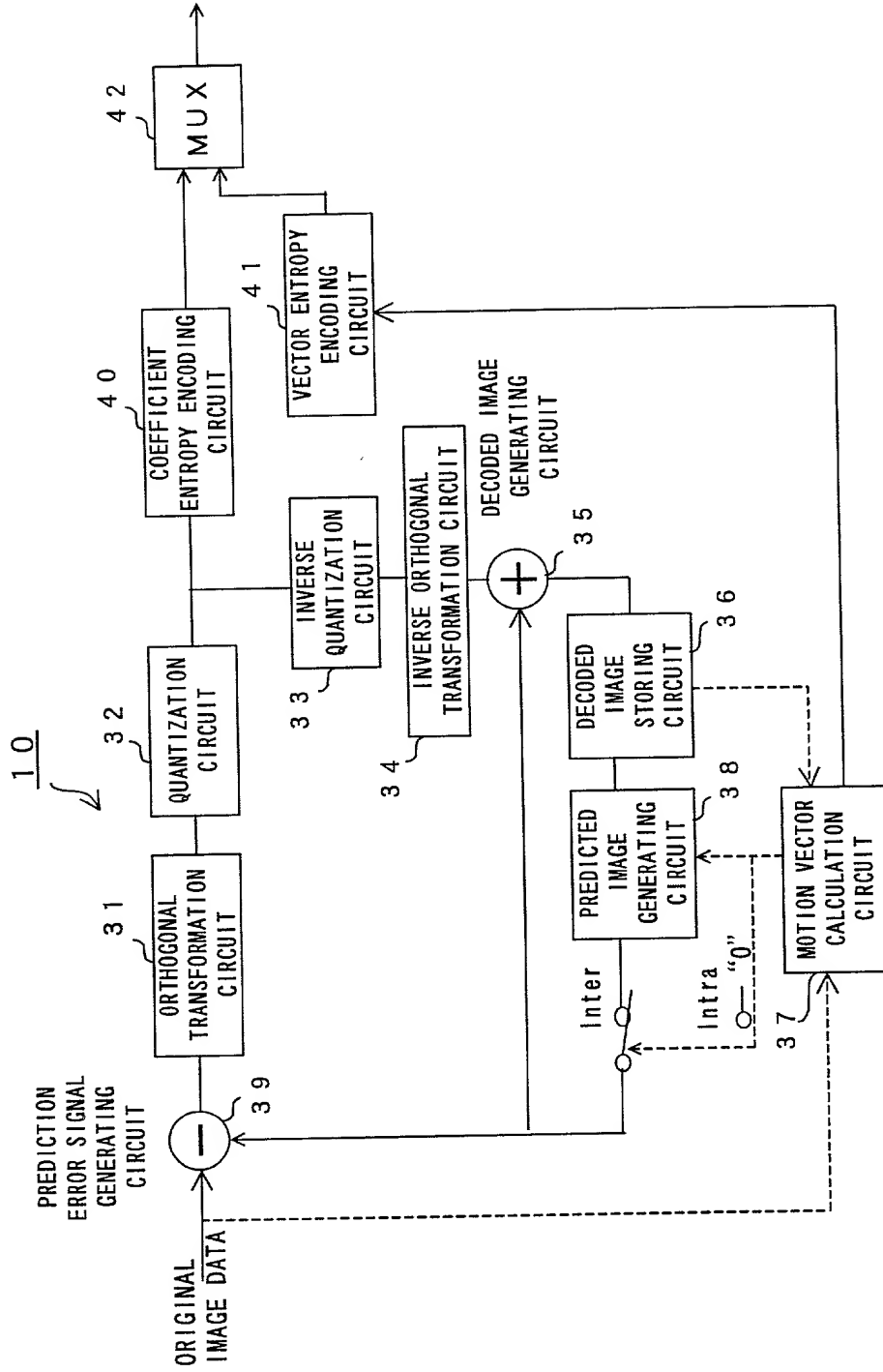


FIG. 7

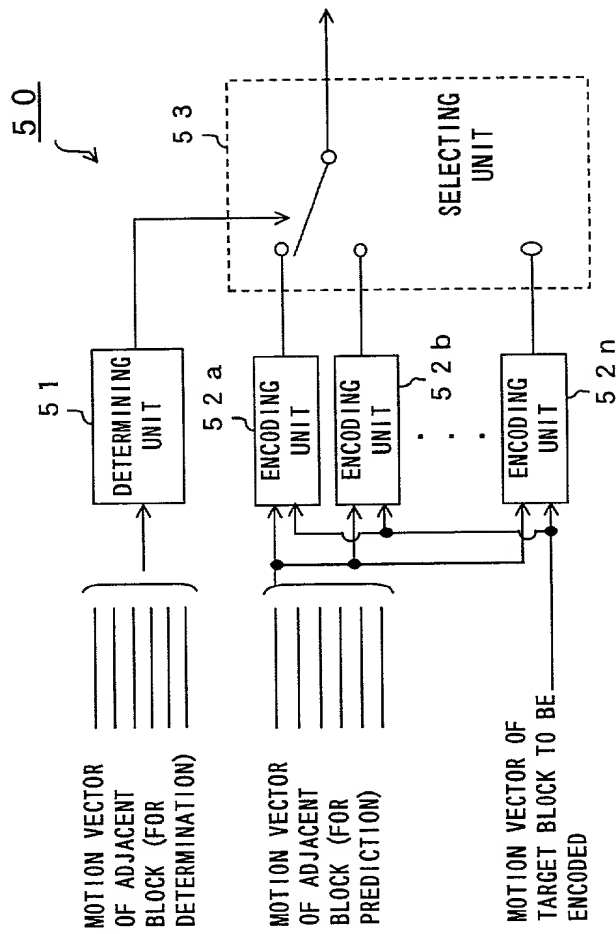


FIG. 8

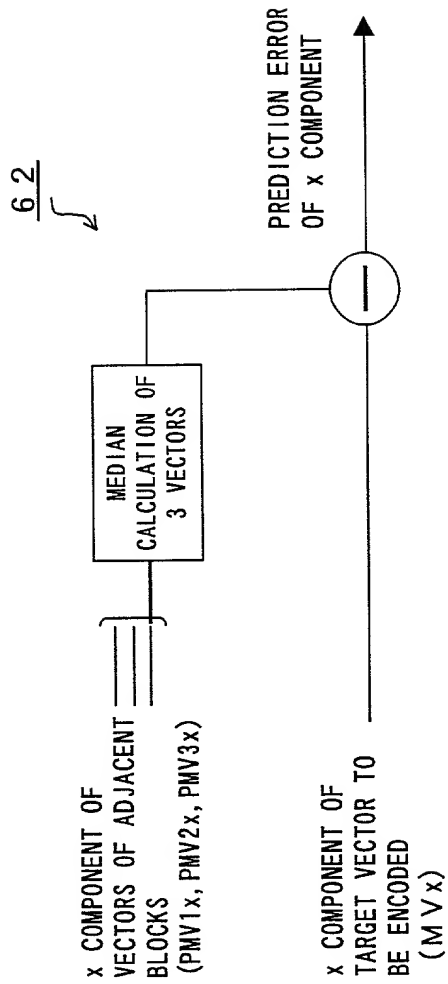
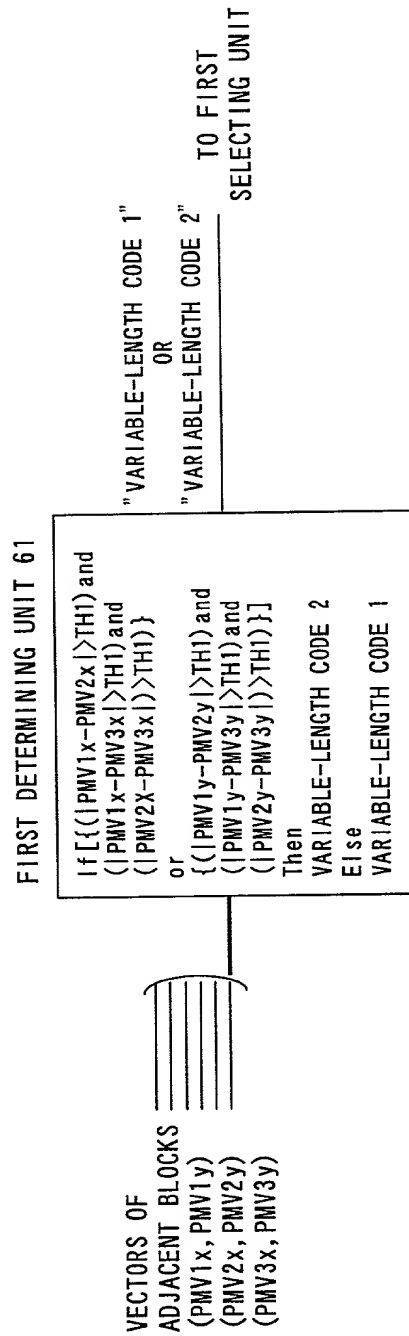


FIG. 10

PREDICTION ERROR	VARIABLE- LENGTH CODES 1	VARIABLE- LENGTH CODES 2
-16.0	000000000101	00000001
-15.5	0000000000111	00000011
-15.0	000000000101	0000011
-14.5	000000000111	0000111
-14.0	000000001001	1101111
-13.5	000000001011	1100011
-13.0	000000001101	0000111
-12.5	000000001111	1000011
-12.0	00000001001	1000001
-11.5	00000001011	1101011
-11.0	00000001101	0000101
-10.5	00000001111	1101001
-10.0	00000010001	1100101
-9.5	00000010011	1100001
-9.0	00000010101	1101101
-8.5	00000010111	0100001
-8.0	00000011001	0001001
-7.5	00000011011	0100011
-7.0	00000011101	0001011
-6.5	00000011111	0101011
-6.0	00000100001	0101001
-5.5	00000100011	101011
-5.0	0000010011	101001
-4.5	0000010101	000111
-4.0	0000010111	100111
-3.5	00000111	010111
-3.0	00001001	010011
-2.5	00001011	10111
-2.0	0000111	10011
-1.5	00011	01101
-1.0	0011	01111
-0.5	011	1111
-0.0	1	001

0.5	010	1110
1.0	0010	01110
1.5	00010	01100
2.0	0000110	10010
2.5	00001010	10110
3.0	00001000	010010
3.5	00000110	010110
4.0	0000010110	100010
4.5	0000010100	000110
5.0	0000010010	101000
5.5	00000100010	101010
6.0	00000100000	0101000
6.5	00000011110	0101010
7.0	00000011100	0001010
7.5	00000011010	0100010
8.0	00000011000	0001000
8.5	00000010110	0100000
9.0	00000010100	1101100
9.5	00000010010	1100000
10.0	00000010000	1100100
10.5	00000001110	1101000
11.0	00000001100	0000100
11.5	00000001010	1101010
12.0	00000001000	1000000
12.5	00000001110	1000010
13.0	00000001100	1000110
13.5	00000001010	1100010
14.0	00000001000	1101110
14.5	00000000110	1100110
15.0	00000000100	0000010
15.5	000000000110	00000010

FIG. 11



F I G. 1 2

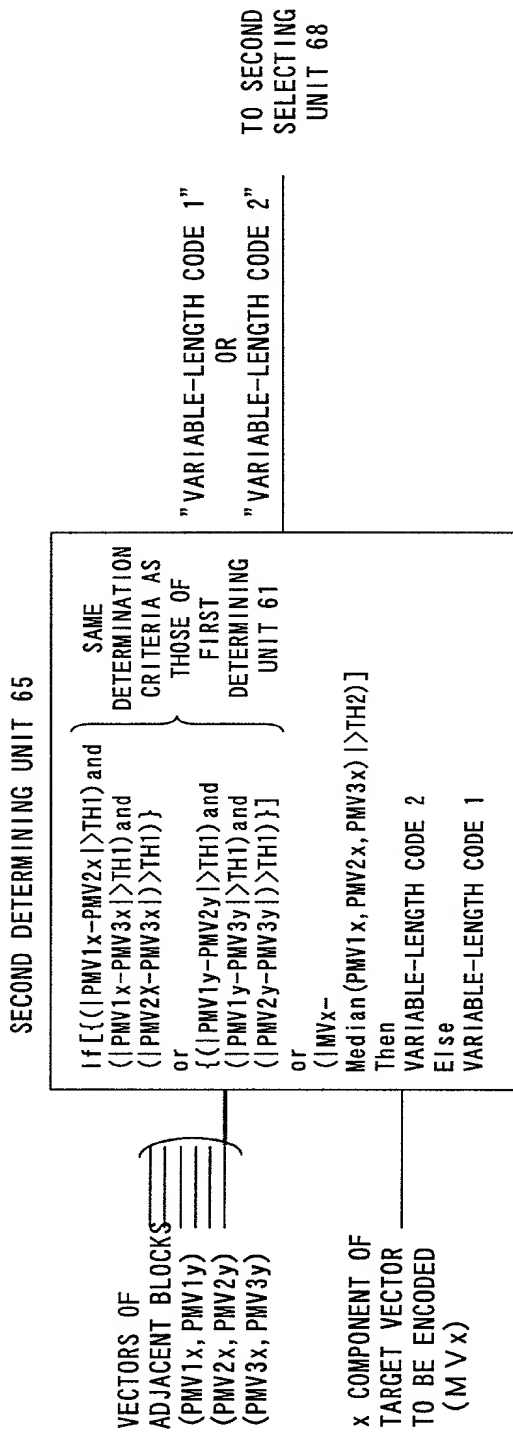


FIG. 13

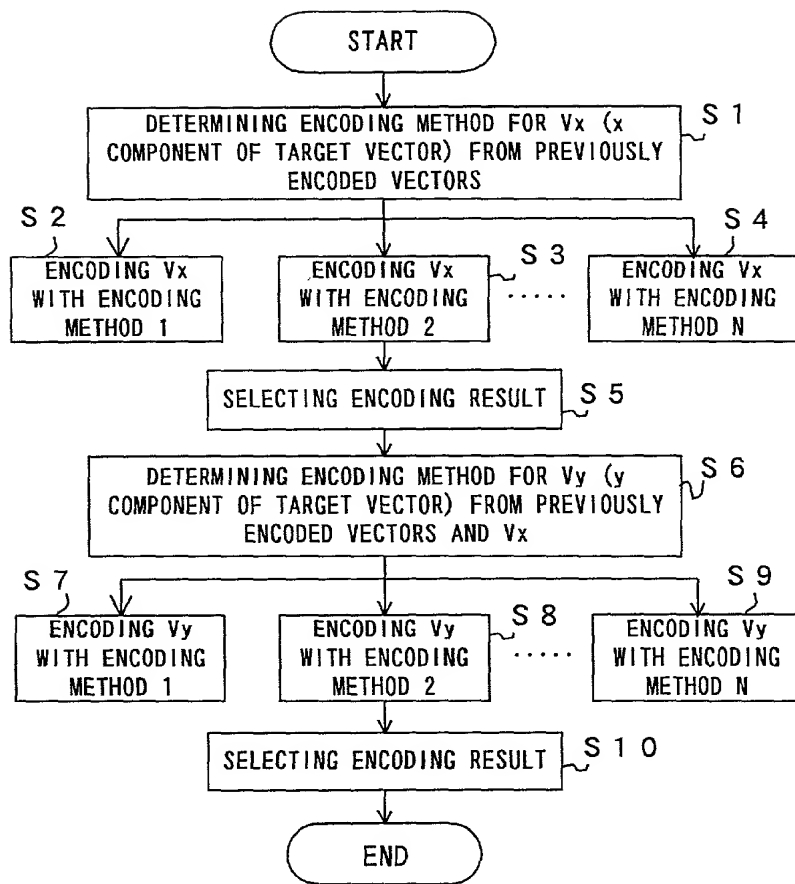


FIG. 14

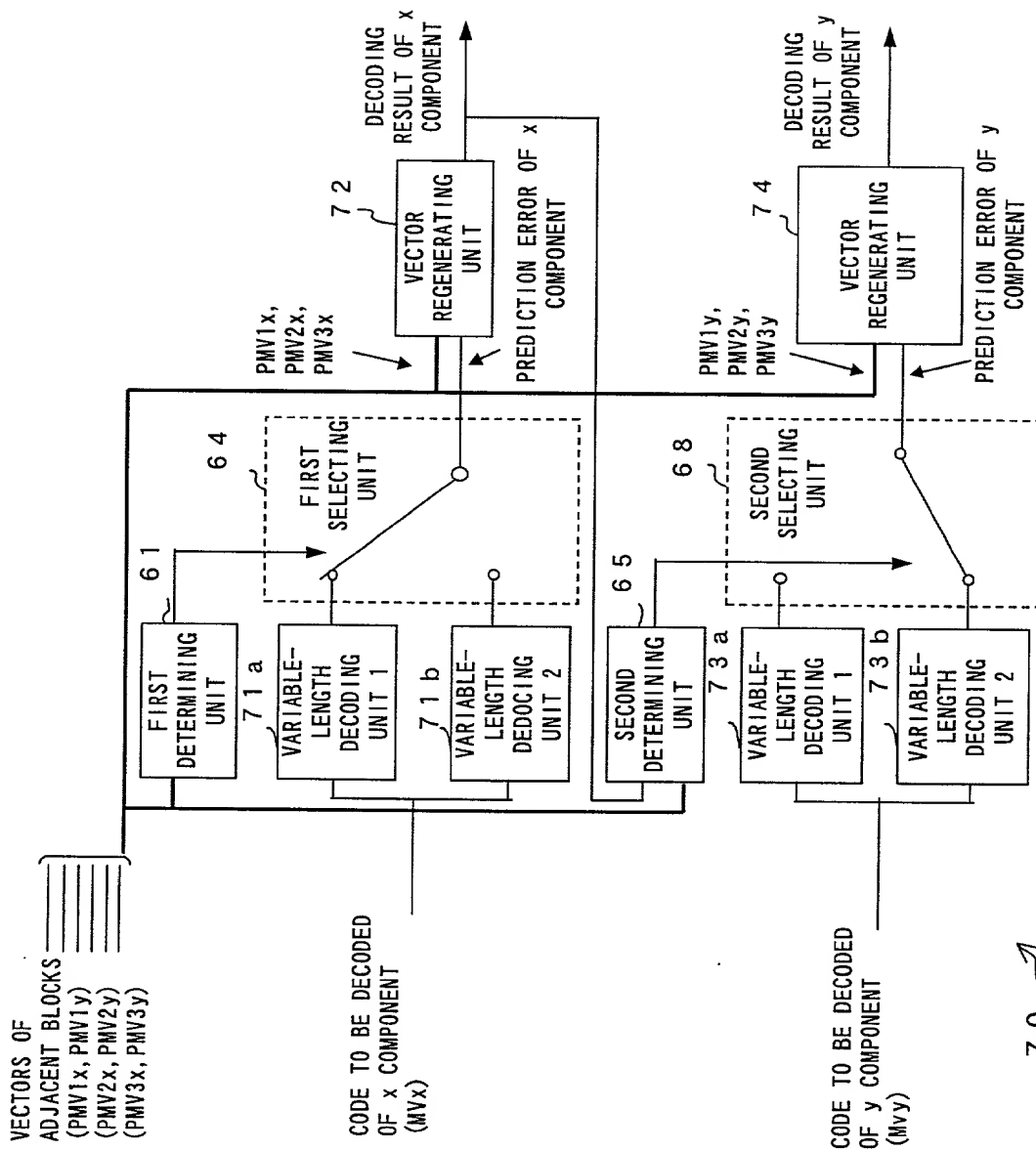


FIG. 15

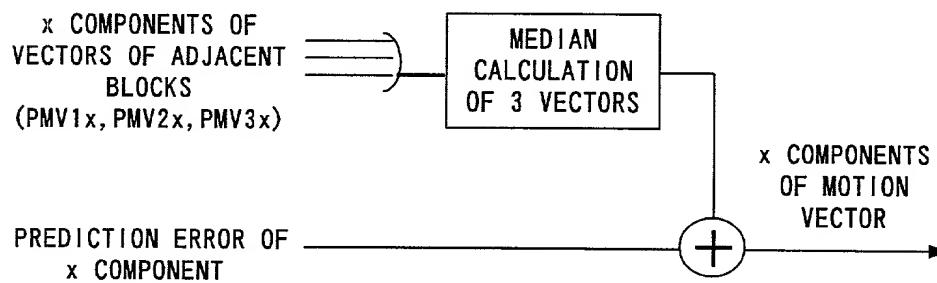


FIG. 16

Under the Paperwork Reduction Act of 1995, no persons are required to respond to a collection of information unless it displays a valid OMB control number.

Declaration and Power of Attorney For Patent Application

特許出願宣言書及び委任状

Japanese Language Declaration

日本語宣言書

下記の氏名の発明者として、私は以下の通り宣言します。

As a below named inventor, I hereby declare that:

私の住所、私書箱、国籍は下記の私の氏名の後に記載された通りです。

My residence, post office address and citizenship are as stated next to my name.

下記の名称の発明に関して請求範囲に記載され、特許出願している発明内容について、私が最初かつ唯一の発明者（下記の氏名が一つの場合）もしくは最初かつ共同発明者であると（下記の名称が複数の場合）信じています。

I believe I am the original, first and sole inventor (if only one name is listed below) or an original, first and joint inventor (if plural names are listed below) of the subject matter which is claimed and for which a patent is sought on the invention entitled

MOTION VECTOR ENCODING DEVICE
AND DECODING DEVICE

上記発明の明細書（下記の欄でx印がついていない場合は、本書に添付）は、

the specification of which is attached hereto unless the following box is checked:

☐ 月 日 に提出され、米国出願番号または特許協定条約国際出願番号を _____ とし、
（該当する場合） _____ に訂正されました。

☐ was filed on _____
as United States Application Number or
PCT International Application Number
_____ and was amended on
_____ (if applicable).

私は、特許請求範囲を含む上記訂正後の明細書を検討し、内容を理解していることをここに表明します。

I hereby state that I have reviewed and understand the contents of the above identified specification, including the claims, as amended by any amendment referred to above.

私は、連邦規則法典第37編第1条56項に定義されるとおり、特許資格の有無について重要な情報を開示する義務があることを認めます。

I acknowledge the duty to disclose information which is material to patentability as defined in Title 37, Code of Federal Regulations, Section 1.56.

Under the Paperwork Reduction Act of 1995, no persons are required to respond to a collection of information unless it displays a valid OMB control number.

Japanese Language Declaration (日本語宣言書)

私は、米国法典第35編119条(a)-(d)項又は365条(b)項に基づき下記の、米国外の国の少なくとも一カ国を指定している特許協力条約365(a)項に基づき国際出願、又は外国での特許出願もしくは発明者証の出願についての外国優先権をここに主張するとともに、優先権を主張している。本出願の前に出願された特許または発明者証の外国出願を以下に、枠内をマークすることで、示しています。

Prior Foreign Application(s)

外国での先行出願
10-308942

(Number)
(番号)

Japan

(Country)
(国名)

(Number)
(番号)

(Country)
(国名)

私は、第35編米国法典119条(e)項に基づいて下記の米国外特許出願規定に記載された権利をここに主張いたします。

(Application No.)
(出願番号)

(Filing Date)
(出願日)

私は、下記の米国法典第35編120条に基づいて下記の米国外特許出願に記載された権利、又は米国外を指定している特許協力条約365条(c)に基づき権利をここに主張します。また、本出願の各請求範囲の内容が米国法典第35編112条第1項又は特許協力条約で規定された方法で先行する米国外特許出願に開示されていない限り、その先行米国外出願書提出日以降で本出願書の日本国内または特許協力条約国際提出日までの期間中に入手された、連邦規則法典第37編1条56項で定義された特許資格の有無に関する重要な情報について開示義務があることを認識しています。

(Application No.)
(出願番号)

(Filing Date)
(出願日)

(Application No.)
(出願番号)

(Filing Date)
(出願日)

私は、私自身の知識に基づいて本宣言書中で私が行なう表明が真実であり、かつ私の入手した情報と私の信じていることに基づき表明が全て真実であると信じていること、さらに故意になされた虚偽の表明及びそれと同等の行為は米国法典第18編第1001条に基づき、罰金または拘禁、もしくはその両方により処罰されること、そしてそのような故意による虚偽の表明を行えば、出願した、又は既に許可された特許の有効性が失われることを認識し、よってここに上記のごとく宣誓を致します。

I hereby claim foreign priority under Title 35, United States Code, Section 119 (a)-(d) or 365(b) of any foreign application(s) for patent or inventor's certificate, or 365(a) of any PCT International application which designated at least one country other than the United States, listed below and have also identified below, by checking the box, any foreign application for patent or inventor's certificate, or PCT International application having a filing date before that of the application on which priority is claimed.

Priority Not Claimed
優先権主張なし

29th/October/1998

(Day/Month/Year Filed)
(出願年月日)

☐

(Day/Month/Year Filed)
(出願年月日)

☐

I hereby claim the benefit under Title 35, United States Code, Section 119(e) of any United States provisional application(s) listed below.

(Application No.)
(出願番号)

(Filing Date)
(出願日)

I hereby claim the benefit under Title 35, United States Code, Section 120 of any United States application(s), or 365(c) of any PCT International application designating the United States, listed below and, insofar as the subject matter of each of the claims of this application is not disclosed in the prior United States or PCT International application in the manner provided by the first paragraph of Title 35, United States Code Section 112, I acknowledge the duty to disclose information which is material to patentability as defined in Title 37, Code of Federal Regulations, Section 1.56 which became available between the filing date of the prior application and the national or PCT International filing date of application.

(Status: Patented, Pending, Abandoned)
(現況: 特許許可済、係属中、放棄済)

(Status: Patented, Pending, Abandoned)
(現況: 特許許可済、係属中、放棄済)

I hereby declare that all statements made herein of my own knowledge are true and that all statements made on information and belief are believed to be true; and further that these statements were made with the knowledge that willful false statements and the like so made are punishable by fine or imprisonment, or both, under Section 1001 of Title 18 of the United States Code and that such willful false statements may jeopardize the validity of the application or any patent issued thereon.

Under the Paperwork Reduction Act of 1995, no persons are required to respond to a collection of information unless it displays a valid OMB control number.

Japanese Language Declaration (日本語宣言書)

委任状: 私は下記の発明者として、本出願に関する一切の手続きを米特許商標局に対して遂行する弁理士または代理人として、下記の者を指名いたします。(弁護士、または代理人の氏名及び登録番号を明記のこと)

James D. Halsey, Jr., 22,729; Harry John Staas, 22,010; David M. Pitcher, 25,908; John C. Garvey, 28,607; J. Randall Beckers, 30,358; William F. Herbert, 31,024; Richard A. Golhofer, 31,106; Mark J. Henry, 36,162; Gene M. Garner II, 34,172; Michael D. Stein, 37,240; Paul I. Kravetz, 35,230; Gerald P. Joyce, III, 37,648; Todd E. Marlette, 35,269; Harlan B. Williams, Jr., 34,756; George N. Stevens, 36,938; Michael C. Soldner, 41,455; Norman L. Ourada, 41,235; Kevin R. Spivak, P-43,148; and William M. Schertler, 35,348 (agent)

書類送付先

POWER OF ATTORNEY: As a named inventor, I hereby appoint the following attorney(s) and/or agent(s) to prosecute this application and transact all business in the Patent and Trademark Office connected therewith (list name and registration number)

Send Correspondence to:

STAAS & HALSEY
700 Eleventh Street, N.W.
Suite 500
Washington, D.C. 20001

直接電話連絡先: (名前及び電話番号)

Direct Telephone Calls to: (name and telephone number)

STAAS & HALSEY
(202) 434-1500

唯一または第一発明者名	Full name of sole or first inventor	Akira NAKAGAWA	
発明者の署名	日付	Inventor's signature	Date
		Akira Nakagawa	June 23, 1999
住所	Residence	Kanagawa, Japan	
国籍	Citizenship	Japan	
私書箱	Post Office Address	c/o FUJITSU LIMITED, 1-1, Kamikodanaka 4-chome, Nakahara-ku, Kawasaki-shi, Kanagawa 211-8588, Japan	
第二共同発明者	Full name of second joint inventor, if any	Taizo ANAN	
第二共同発明者	日付	Second inventor's signature	Date
		Taizo Anan	June 23, 1999
住所	Residence	Kanagawa, Japan	
国籍	Citizenship	Japan	
私書箱	Post Office Address	c/o FUJITSU LIMITED, 1-1, Kamikodanaka 4-chome, Nakahara-ku, Kawasaki-shi, Kanagawa 211-8588, Japan	

(第三以降の共同発明者についても同様に記載し、署名をする)

(Supply similar information and signature for third and subsequent joint inventors.)

第三共同発明者		Full name of third joint inventor, if any Eishi MORIMATSU	
第三共同発明者	日付	Third inventor's signature <i>Eishi Morimatsu</i>	Date June 23, 1999
住 所		Residence Kanagawa, Japan	
国 籍		Citizenship Japan	
私書箱		Post Office Address c/o FUJITSU LIMITED, 1-1, Kamikodanaka 4-chome, Nakahara-ku, Kawasaki-shi, Kanagawa 211-8588, Japan	
第四共同発明者		Full name of fourth joint inventor, if any Takashi ITOH	
第四共同発明者	日付	Fourth inventor's signature <i>伊藤 隆</i>	Date June 23, 1999
住 所		Residence Kanagawa, Japan	
国 籍		Citizenship Japan	
私書箱		Post Office Address c/o FUJITSU LIMITED, 1-1, Kamikodanaka 4-chome, Nakahara-ku, Kawasaki-shi, Kanagawa 211-8588, Japan	

第五共同発明者		Full name of fifth joint inventor, if any	
第五共同発明者	日付	Fifth inventor's signature	Date
住 所		Residence	
国 籍		Citizenship	
私書箱		Post Office Address	
第六共同発明者		Full name of sixth joint inventor, if any	
第六共同発明者	日付	Sixth inventor's signature	Date
住 所		Residence	
国 籍		Citizenship	
私書箱		Post Office Address	

(第七以降の共同発明者についても同様に
記載し、署名をすること)

(Supply similar information and signature for
seventh and subsequent joint inventors.)